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(54) EXTERNAL LEAD JUNCTION METHOD

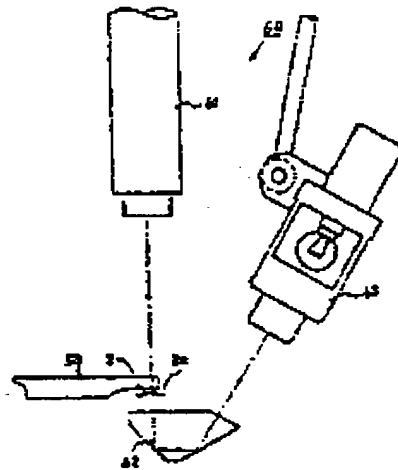
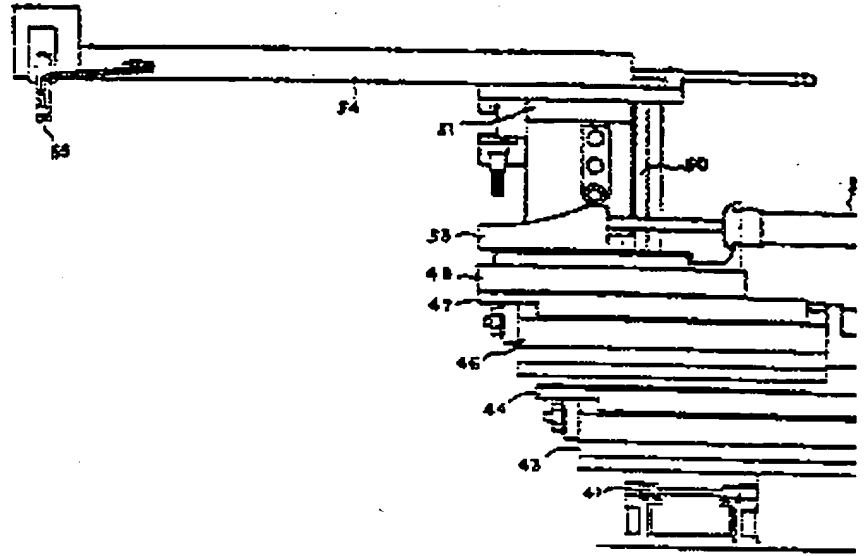
(57) Abstract:

PURPOSE: To render a junction position accuracy higher and obtain uniform images to make processing works reliable by performing an operation of both amount and direction of relative position shifts occurred in lead frames of a solid device and determining positioning to a prescribed position.

CONSTITUTION: Lights are projected on a camera so as to transmit a solid device 2 held at a vacuum suction head 55 from downward and images that are in the forms of external lead 2a obtained by the above transmission are caught by the camera 61. The images are treated by a recognition part and relative position shifts to positions of lead frames 3 are operated and these position shifts are reverted to a moving control system of XY direction moving tables 43, 46, and 49 to be used for transferring the solid device 2 and then positioning of its solid device 2 is determined to prescribed position of the lead frames. Thus, junction positions can be determined accurately.

Furthermore, transmitted lights from downward are so effectively used to recognize holding positions of the solid device 2 that uniform images are obtained by taking a picture of shadows produced by the above transmission of lights irrespective of various aspects arisen in the case of cutting the external leads and it is possible to perform reliable processing works without making automatic recognition errors.

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Title: **JP63020847A2: EXTERNAL LEAD JUNCTION METHOD**

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Abstract:



Purpose: To render a junction position accuracy higher and obtain uniform images to make processing works reliable by performing an operation of both amount and direction of relative position shifts occurred in lead frames of a solid device and determining positioning to a prescribed position.

Constitution: Lights are projected on a camera so as to transmit a solid device 2 held at a vacuum suction head 55 from downward and images that are in the forms of external lead 2a obtained by the above transmission are caught by the camera 61. The images are treated by a recognition part and relative position shifts to positions of lead frames 3 are operated and these position shifts are reverted to a moving control system of XY direction moving tables 43, 46, and 49 to be used for transferring the solid device 2 and then positioning of its solid device 2 is determined to prescribed position of the lead frames. Thus, junction positions can be determined accurately. Furthermore, transmitted lights from downward are so effectively used to recognize holding positions of the solid device 2 that uniform images are obtained by taking a picture of shadows produced by the above transmission of lights irrespective of various aspects arisen in the case of cutting the external leads and it is possible to perform reliable processing works without making automatic recognition errors.

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